

IN THE SPECIFICATION:

Please replace the paragraph 2, page 6, and insert instead the following paragraph:

--The essence of the invention comprises imaging illuminating surfaces onto the surface of the object to be measured. The impingement of the surface of the object to be measured occurs from the most different directions of incidence by employing a diffusely illuminating surface instead of a sharply bundled laser beam. The course of beams out of an illuminating surface, wherein the course of beams is focused on the surface of the container, contains a large bandwidth of light bundles, which impinge onto the container surface from different angles of incidence. This assures that parts of the course of the beams are always reflected back into the receiving optics despite the grained, uneven surface of the object to be measured, even though other bundles out of the beam course are not available based on these surface defects. Thus always two reflexes are generated on the opto-electronic image resolving sensor.--

Please replace the paragraph 3, page 8, (second amendment) and insert instead the following paragraph:

--At the same time the lens 22 is disposed following to the illuminating surface 21, wherein the illuminating surface 21 is again realized by a line shaped light exit opening of a light guide. Again this lens generates a parallel beam from the diverging beam which exits from the light guide 21, wherein the parallel beam is directed to the semi permeable mirror 23 into the objective 24, wherein the objective 24 also focuses the beams under an angle of incidence onto the surface of the container 1. This angle of incidence corresponds to the exit angle from the surface of the container 1 of the reflexes derived from the first illuminating surface 11. Similarly two reflexes derived from the front side 1.1 and from the inner side or rear side 1.2 of the container are reflected back from the surface of the container 1. These two reflexes are imaged through the objective 14, through the semi permeable mirror 13 and further through the lens 15 onto the line sensor 16. The line sensor 16 is again connected to the controller 3, wherein the controller 3 also determines the distance between these two reflexes and uses the distance between these two reflexes as a base for the further calculation of the wall thickness. The wall thickness is finally determined by an averaging of the distances determined with the two sensors 16 and 26.--